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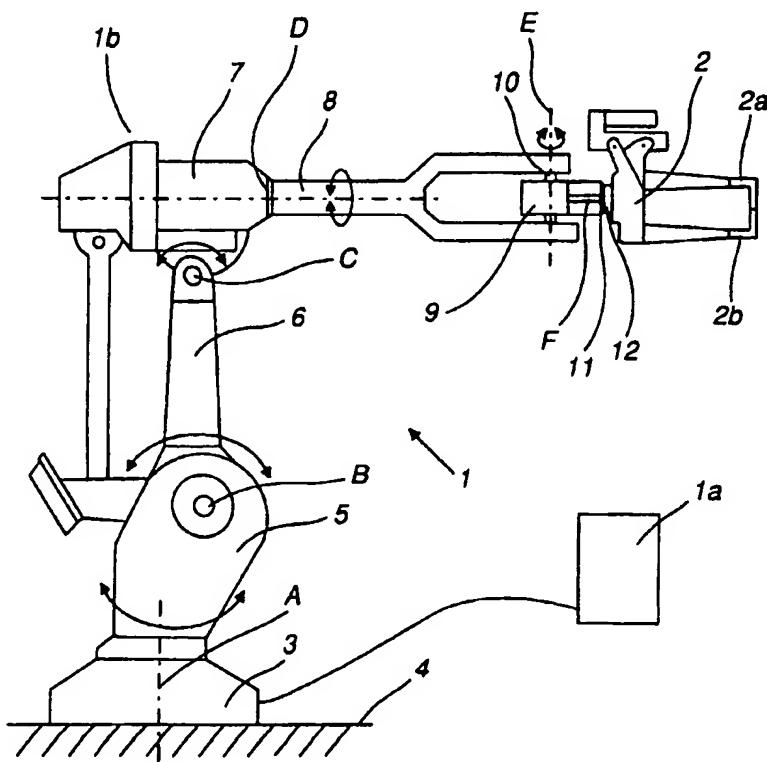
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(54) Title: METHOD IN INDUSTRIAL ROBOT SYSTEM



(57) Abstract: The invention comprises a method of an industrial robot (1), comprising a control unit (7) and a manipulator (1) including a tool (3) comprising a defined TCP and a device for determining a distance error (d*) between an inaccurately programmed position (plp) for a spot (1) on a surface (5) of a work piece (4) and a corresponding actual position (pla).

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